

Pub. E10 D6 compl.
rejected until the old one is fully completed, also servo calculations compensate time normalization based on the overrun information -- in effect, when overrun occurs, it is as though the clock interval has been doubled in duration.

✓ Please replace the paragraph starting on page 21, line 15 with the following:

D7
The force contributions to the various axes are appropriately scaled and applied to a running sum of contributions (which are summed across multiple control function calls). When the control/command function lists are completed, the resulting final set of forces (or torques) become the values set into the output digital to analog interfaces.

✓ Please replace the paragraph starting on page 22, line 29 with the following:

Pub. E12 D8
For cases where D is larger than R_{max} , the force contribution, F_{in} and F_{out} , are $[0,0]$. For cases where D is less than R , F_{out} is zero and F_{in} is computed as a force directed toward the center, X_c, Y_c , from the current joint coordinates, X, Y . This computation is as follows:

IN THE CLAIMS:

Claims 19-45 are pending. Claims 30-31 are amended. Claims 35-45 are allowed. A marked up copy of all amended claims are in Appendix B. A clean copy of all pending claims are in Appendix C.